Harmonic Drive AG

User Manual

YukonDrive

PROFI® PROCESS FIELD BUS BUS

Harmonic Drive AG

1003375 06/2012

This document details the functionality of the following equipment variants:

YukonDrive-10xx-xEx-xx

PROFIBUS for YukonDrive user manual
Date: 06/2012
We reserve the right to make technical changes.

Technical alterations reserved.
The contents of our documentation have been compiled with greatest care and in compliance with our present status of information.

Nevertheless we would like to point out that this document cannot always be updated parallel to the technical further development of our products. Information and specifcations may be changed at any time. For information on the latest version please refer to www.harmonicdrive.de

Table of contents

How to use this manual 6

1 General 8

1.1 Measures for your Safety 8

1.2 Introduction to PROFIBUS 9

1.3 System requirements 9

1.4 Further documentation 9

2 Commissioning the PROFIBUS Interface 10

2.1 Connections and user controls 10

2.2 Plug configuration for the PROFIBUS cable 11

2.3 Bus termination 12

2.4 Setting the drive address 13

2.5 Operating displays 14

2.6 GSD file 15

3 Cyclic data transmission – DPV0 16

3.1 Parameter process data objects (PPO) 16

3.1.1 Standard "PROFIdrive" telegrams 16

3.1.2 User-specific PPOs 19

3.1.3 PPKW parameter channel 23

3.2 Master control word 26

3.2.1 Jog mode speed mode 28

3.2.2 Jog mode positioning mode 29

3.2.3 Jog mode reference value parameter 29

3.3 Drive status word 30

3.4 Drive status machine 32

4 Acyclic data transmission – DPV1 36

4.1 Telegram type SD2 used for DPV1 services 36

4.2 Examples of request and reply telegrams 44

5 Operating modes 48
5.1 Speed Control 48
5.2 Speed control circuit and associated control parameters 49
5.3 Position control 51
5.4 Position control circuit and associated control parameters 52

6 Homing 54
6.1 Homing runs performed by the drive 54
6.2 Homing run speed 54
6.3 Homing run acceleration 54
6.4 Zeroing offset 54
6.5 Homing cams, limit switches 54
6.6 Homing run methods 56

7 Examples of commissioning using manufacturer-specific telegrams 58
7.1 Position control using PPO 5 58
7.2 Conversion of reference values and actual values using factor group parameters 60
7.3 Examples for setting the user factor group 62
7.4 Speed control using PPO 2 62
7.4.1 Speed input 64
7.5 Mappable parameters 64

8 PROFIBUS parameters 66

Appendix Glossary 70

How to use this manual

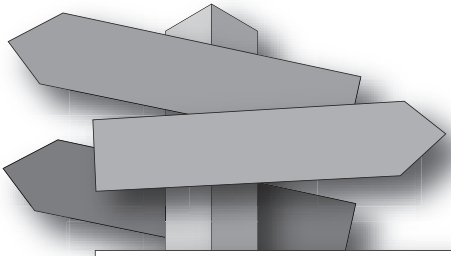
Dear user!

This manual is intended for use by project engineers, commissioning engineers and programmers of drives and automation solutions involving the PROFIBUS field bus. It assumes that you have received appropriate training on PROFIBUS and that you have access to relevant reference books. We assume that your drive has already been commissioned – if not, please first refer to the user manual.

Note: This manual relates to the YukonDrive positioning drive system.

Pictograms

	Attention! Incorrect operation may damage the drive or cause it to malfunction.
	Danger from electrical tension! Improper conduct may endanger human life.
	Danger from rotating parts! The drive may start up automatically.
	Note: Useful information



1 General **1**

2 Commissioning the Profibus interface **2**

3 Cyclic data transmission – DPV0 **3**

4 Cyclic data transmission – DPV1 **4**

5 Operating modes **5**

6 Homing **6**

7 Commissioning examples **7**

8 PROFIBUS parameters **8**

Appendix: Key words directory

1. General

1.1 Measures for your Safety

Drive controllers of the YukonDrive family are quick and easy to handle. For your own safety and for the safe functioning of your device, please be sure to observe the following points::

• Follow the safety instructions!
Electric drives are subject to certain hazards: • Electric voltages > 230 V/460 V: Dangerously high voltages may still be present 10 minutes after the power is switched off. So always make sure the system is no longer live! • Rotating parts • Hot surfaces
Your qualification: • In order to prevent personal injury or damage to property, only personnel with electrical engineering qualifications may work on the device. • Knowledge of the national accident prevention regulations (such as VBG4 in Germany) • Knowledge of structure and networking using the CAN field bus
During installation observe the following instructions: • Always comply with the connection conditions and technical specifications. • Standards for electrical installation, e.g. cable cross-sections, screening etc. • Do not touch electronic components and contacts (electrostatic discharge may destroy components)

1.2 Introduction to PROFIBUS

The PROFIBUS implementation in YukonDrive is based on the PROFIdrive profile "PROFIBUS PROFdrive profile version 4.0" dated August 2005.

Performance features in key words

- Data transmission using two-wire twisted pair cable (RS 485)
- Transmission rate: optionally 9.6 K, 19.2 K, 45.45 K, 93.75 K, 187.5 K, 500 K, 1.5 M, 3 M, 6 M or 12 MBaud
- Automatic Baud rate detection
- PROFIBUS address can be set using the rotary coding switches or alternatively using the addressing parameters
- Cyclic data exchange reference and actual values using DPV0
- Acyclic data exchange using DPV1
- Synchronisation of all connected drives using freeze mode and sync mode
- Reading and writing drive parameters using the PKW channel or DPV1

1.3 System requirements

It is assumed that you have access to a standard PROFIBUS set-up program or a PROFIBUS interface driver.

1.4 Further documentation

- User manual for commissioning the drive device
- User manual for further parameterisation to customise the application.
- The user manual can be downloaded as a PDF file from the "Service" area on our Homepage www.harmonicdrive.de
- CiA DS-301 (Rev. 4.0): Application Layer and Communication Profile
- CiA DSP-402 (Rev. 2.0): Device Profile Drives and Motion Control
- Profibus User Organisation „Profidrive - Profil Drive Technology for Profibus and Profinet" Version 4.1, May 2006, Order no. 3.172

2. Commissioning the PROFIBUS Interface

2.1 Connections and user controls

The connections and user controls for the PROFIBUS interface are shown schematically in Figure 2-1. The LEDs H1, H2, H3 act as status indicators. The rotary coding switches S1 and S2 can be used to set the PROFIBUS address for the drive. The PROFIBUS cable is connected to the plug X14.

Table 2.1 PROFIBUS options card

Front plate	No.	Comments
	H1	LED for status indication (yellow)
	H2	LED for status indication (red)
	H3	LED for status indication (green)
	X14	PROFIBUS cable connection

2.2 Plug configuration for the PROFIBUS cable

The PROFIBUS is connected using a nine-pin sub-D plug. The pin assignment is shown in Fig. 2-2 and described in Table 2.1.

Figure 2.1 Pin assignment of sub-D-plug connector

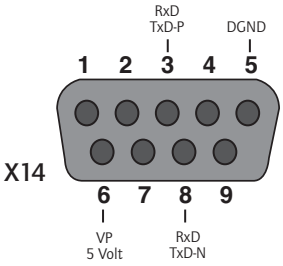


Table 2.2 Description of pin assignment

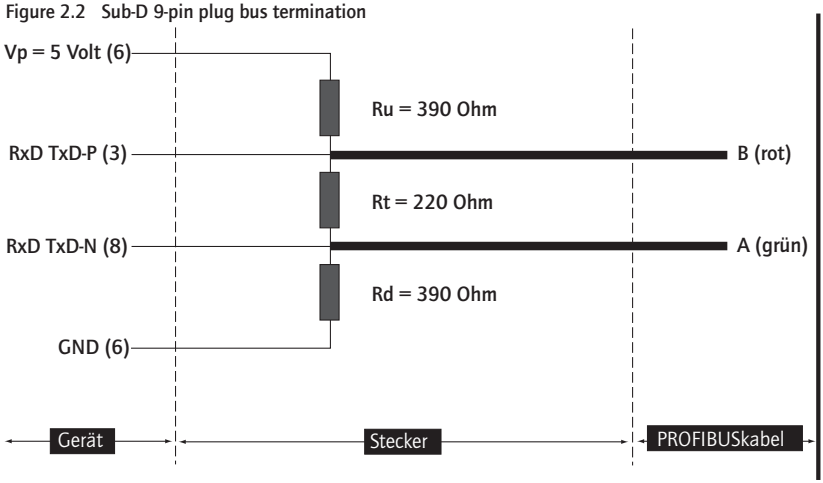
PIN	RS-485	Signal	Beschreibung
1		SHIELD	Earthed shield
2		*RP*	*Reserved for power supply via the bus*
3	B/B' (rot)	RxD / TxD-P	Send and receive data (+)
4		*CNTR-P*	*Control signal for repeater (+)*
5	C/C'	DGND	Data reference potential and power supply to terminating resistor (-)
6		VP	Power supply for terminating resistor (+)
7		*RP*	*Reserved for power supply via the bus*
8	A/A' (grün)	RxD / TxD-N	Send and receive data (-)
9		*CNTR-N*	*Control signal for repeater (-)*

The signals shown with cursive letters in the table have to be provided by the user, if requested. The control signals used for the repeaters are optional, and the power supply for the terminating resistors is provided by the device.

2.3 Bus termination

If the drive controller is initially at the end of the bus system, a plug with an integral terminating resistor Rt should be used. In addition to the cable terminating resistor in accordance with the EIA-RS-485 standard, a pull-down resistor Rd against the data reference potential DGND and a pull-up resistor Ru against VP are provided. This ensures a defined no-load potential of 1.1 Volt between pins 3 and 8. In a made-up PROFIBUS cable these resistors are all incorporated as standard in the PROFIBUS plug and the terminating resistor can be activated using a switch on the PROFIBUS plug. The following figure shows a Sub-D 9-pin plug bus termination.

Figure 2.2 Sub-D 9-pin plug bus termination



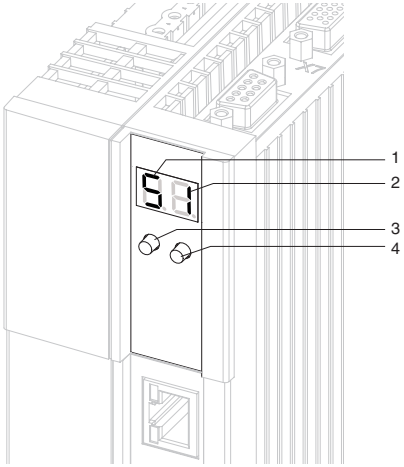
2.4 Setting the drive address

The drive address can be assigned using parameter 918 (COM_DP_Address). The drive address is set only after a 24 V reset of the device. For all devices, the bus address can be set via the buttons on the device, refer to the Operating Manual YukonDrive. Via the devices operating panel, a diagnosis of the YukonDrive is possible.

The control unit comprises the following elements that are all positioned on the front:

- 2-digit 7-segment display (1, 2)
- 2 buttons (3, 4)

Figure 2.3 Integrated control unit YukonDrive



The following functions and indications are available:

- Indication of the device status
  The device status is indicated after switching on the control supply. If an entry is not made using the buttons for 60 seconds, the display returns to the display of the device status.
- Indication of the device error status
  On the occurrence of an error in the device, the display is immediately switched to the indication of the error code.
- Parameter setting (indication „PA“)
  Reset the device parameter settings to the factory setting
- Ethernet IP address setting (indication „IP“)
  Setting for the Ethernet IP address as well as the subnet mask
- Fieldbus settings (indication „Fb“)
  Setting e.g. for the fieldbus address

2.5 Operating displays

Options module: Three LEDs are mounted on the options card; these give indications regarding the current operating status of the module. In Tables 2-2 and 2-3 the operating statuses of the PROFIBUS module are listed, based on the various LED illumination combinations.

Table 2.3 Self test after power on

LED 3, green	LED 2, red	Status
		Reset (after switching on)
		ASIC RAM test and initialisation
		End of ASIC RAM test and initialisation

Table 2.4 Operation diagnostics

LED 3, grün	LED 2, rot	Status
		Seeking Baud rate after switching on without bus connection
		Seeking Baud rate after the bus connection has already been established
		Awaiting parameterisation data

Table 2.4 Operation diagnostics

LED 3, green	LED 2, red	Status
		Communication: Data exchange without acyclic master class 2 connection. Yellow LED lights up.
		Communication: Data exchange “clear state”
		Incorrect parameterisation data
		Incorrect configuration data
		Communication: Data exchange with acyclic master class 2 connection.

Table 2.5 Data exchange

LED 1, yellow	Status
	Device is exchanging data

2.6 GSD file

The device master data file contains the summary of the device features in a standardised form. The device features include for instance the device name, the bus timing, the extended services available and the modules that can be selected (telegram types). In order to use different telegram types, the GSD file must be linked in at the configuration phase of the PROFIBUS network. This file contains, as well as the standard “Profidrive Profile” telegrams, additional manufacturer-specific telegram types.

3. Cyclic data transmission – DPV0

3.1 Parameter process data objects (PPO)

The establishment of communications between a class 1 master and the YukonDrive drive controller is essentially performed in three phases. Firstly the YukonDrive is parameterised with the current bus parameters, monitoring times and drive-specific parameters (phase1). In the configuration phase a configuration sent by the master is compared with the actual YukonDrive configuration (phase 2). Once these two phases have been completed successfully, the cyclic user data traffic starts (phase 3).

The various telegram types (Parameter Process Data Objects - PPO) are prepared in the GSD file. These PPOs form the basis of the configuration phase. The project engineer knows from the GSD file how many bytes are required for the input and output data for PROFIBUS communication between the master and the drive controller and can use this information to perform his settings in the configuration tool. As well as the standard telegrams in accordance with the "PROFIdrive – Profile", there are additional userspecific telegram types. In addition to the PZD process data channel, the user-specific telegram make partial use of a PKW parameter channel.

3.1.1 Standard "PROFIdrive" telegrams

The table below lists firstly the standard "Profidrive" telegrams that are supported by the drive controller. Table 3-1 explains the abbreviations used to assign standard telegrams to a specific process data channel. The process data channel (abbreviated to PZD) is grouped by words.

Table 3.1 Abbreviations

Abbreviation	Name	Number of words
STW1	Control word 1	1
STW2	Control word 2	1
ZSW1	Status word 1	1
ZSW2	Status word 2	1
NSOLL_A	Speed reference	1
NIST_A	Actual speed	1
SATZANW	Set selection (from the driving set table)	1
AKTSATZ	Current set selection (from the driving set table)	1
XSOLL_A	Reference position	2
XIST_A	Actual position	2
TARPOS_A	Reference destination position	2
VELOCITY_A	Reference speed	2

Standard telegram 1 is a defined telegram type for speed control. It consists of two input words and two output words as shown in the following table.

Table 3.2 Standard telegram 1

PZD number	1	2
Reference values	STW1	NSOLL_A
PZD number	**1**	**2**
Actual values	ZSW1	NIST_A

Standard telegram 7 is a defined telegram type for selecting the driving set. In total 16 driving sets saved in the drive can be selected. The telegram type comprises 2 input words and two output words as in the following table.

Table 3.3 Standard telegram 7

PZD number	1	2
Reference values	STW1	SATZANW
PZD number	**1**	**2**
Actual values	ZSW1	AKTSATZ

Standard telegram 8 is a defined telegram type for positioning with the facility for specifying a positioning speed. It consists of 5 input words and 5 output words as shown in the following table.

Table 3.4 Standard telegram 8

PZD Nummer	1	2	3	4	5
Reference values	STW1	XSOLL_A		STW2	NSOLL_A
PZD Nummer	**1**	**2**	**3**	**4**	**5**
Actual values	ZSW1	XIST_A		ZSW2	NIST_A

Standard telegram 9 is a defined telegram type for positioning. It consists of 6 input words and five output words as shown in the following table.

Table 3.5 Standard telegram 9

PZD Nummer	1	2	3	4	5	6
Reference values	STW1	TARPOS_A		STW2	VELOCITY_A	
PZD Nummer	**1**	**2**	**3**	**4**	**5**	
Actual values	ZSW1	XIST_A		ZSW2	NIST_A	

Every standard telegram in the device is described in the GSD file by a PROFIdrive Profile configuration identifier (ID). The following table shows these identifiers for the selected standard telegrams.

Table 3.6 Identifier

Telegrammtyp	Datenbereich	Identifier (ID)
Standard telegram 1	2 output words and 2 input words	0xC3 0xC1 0xC1 0xFD 0x00 0x01
Standard telegram 7	2 output words and 2 input words	0xC3 0xC1 0xC1 0xFD 0x00 0x07
Standard telegram 8	5 output words and 5 input words	0xC3 0xC4 0xC4 0xFD 0x00 0x08
Standard telegram 9	6 output words and 5 input words	0xC3 0xC5 0xC4 0xFD 0x00 0x09

3.1.2 User-specific PPOs

As well as the standard telegrams that are supported there are in addition further userspecific PPOs (Parameter Process data Objects). The following PPOs are also transmitted cyclically and in addition to the PZD process data channel partially contain a PKW parameter channel, thereby allowing access to the drive parameter values.

Table 3.6 User-specific Parameter Process data Objects

PPO	PKW				PZD									
1	PKE	IND	PKW 1	PKW 2	STW/ ZSW	Ref./ Actual Value	-	-	-	-	-	-	-	-
2	PKE	IND	PKW 1	PKW 2	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	-	-	-	-
3*	-	-	-	-	STW/ ZSW	Ref./ Actual Value	-	-	-	-	-	-	-	-
4	-	-	-	-	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	-	-	-	-
5	PKE	IND	PKW 1	PKW 2	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	PZD 7	PZD 8	PZD 9	PZD 10
	-	-	-	-	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	-	-	-	-	-	-
	PKE	IND	PKW 1	PKW 2	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	-	-	-	-	-	-
	-	-	-	-	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	PZD 7	PZD 8	-	-
	PKE	IND	PKW 1	PKW 2	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	PZD 7	PZD 8	-	-
	-	-	-	-	STW/ ZSW	Ref./ Actual Value	PZD 3	PZD 4	PZD 5	PZD 6	PZD 7	PZD 8	PZD 9	PZD 10

(*) PPO3 is the standard telegram 1

In the drive parameter list there exist two signal tables, which contain all the process data that can be cyclically read and written for the PROFIBUS communications DPV0. All possible process data signals that can be written can be found in the signal table 1284 (COM_DP_SignalList_Write) and all possible process data signals that can be read can be found in the signal table 1285 (COM_DP_SignalList_Read). The most important parameters that can be read and written are also documented in Chapter 6.

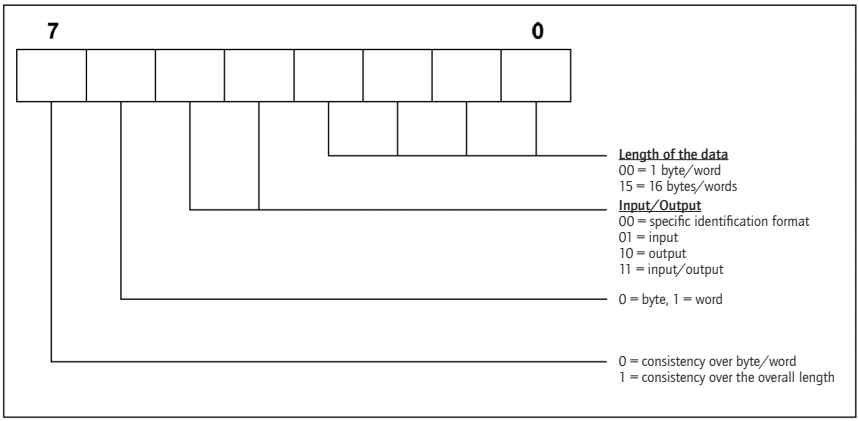
The process data signals that can be written can be configured in the signal table 915 (COM_DP_PZDSelection-Write). The number of process data available to be written are determined by the PPO type that is selected.

The process data signals that can be read can be configured in the signal table 916 (COM_DP_PZDSelection-Read). The number of process data available to be read are also determined by the PPO type that is selected. When using standard telegrams the process data signals in the signal tables are automatically configured by the firmware.

A maximum of 15 process data signals can be „mapped". Here both words and double words can be used.

The user-specific drive telegram types are described by a configuration identifier (ID) in the GSD file. This describes the structure of the cyclic report data using a special identification format shown in the figure below.

Figure 3.1 Identification format (Identifier)



After the parameterisation phase, the master sends the drive a configuration telegram containing this special identification (ID). On receipt of this, the drive compares the data in the configuration telegram with the configuration held in the drive. The identifier determined by the PPO type can be found in the GSD file under the heading "Modules". The following table shows these identifiers for the user-specific telegrams.

Table 3.8 Listing of identifiers

PPO Type	Identifier (ID) Hex	Identifier (ID) Bin	Evaluation using the special identification format (Figure 3.6)	Reference to Table AK slave-master
1	0xF3 0xF1	1111 0011 1111 0001	4 words input/output data (consistent overall length) 2 words input/output data (consistent overall length)	PKW - channel PZD - channel
2	0xF3 0xF5	1111 0011 1111 0101	4 words input/output data (consistent overall length) 6 words input/output data (consistent overall length)	PKW - channel PZD - channel
3	0xF1	1111 0001	2 words input/output data (consistent overall length)	PZD - channel
4	0xF5	1111 0101	6 words input/output data (consistent overall length)	PZD - channel
5	0xF3 0xF9	1111 0011 1111 1001	4 words input/output data (consistent overall length) 10 words input/output data (consistent overall length)	PKW - channel PZD - channel
	0xF3	1111 0011	4 words input/output data (consistent overall length)	PZD - channel
	0xF3 0xF3	1111 0011 1111 0011	4 words input/output data (consistent overall length) 4 words input/output data (consistent overall length)	PKW - channel PZD - channel
	0xF7	1111 0111	8 words input/output data (consistent overall length)	PZD - channel
	0xF3 0xF7	1111 0011 1111 0111	4 words input/output data (consistent overall length) 8 words input/output data (consistent overall length)	PKW - channel PZD - channel
	0xF9	1111 1001	10 words input/output data (consistent overall length)	PZD - channel
	0xC0 0xCD 0xCD		14 words input/output data (consistent overall length)	
	0xF3 0xC0 0xCD 0xCD		14 words input/output data (consistent overall length)	PKW - channel
	0xC0 0xD1 0xD1		18 words input/output data (consistent overall length)	
	0xF3 0xC0 0xD1 0xD1		18 words input/output data (consistent overall length)	PKW - channel
	0xC0 0xD5 0xD5		22 words input/output data (consistent overall length)	

Table 3.8 Listing of identifiers, prosecution

PPO type	Identifier (ID) Hex	Identifier (ID) Bin	Evaluation using the special identification format (Figure 3.6)	Reference to Table AK slave-master
	0xF3 0xC0 0xD5 0xD5		26 words input/output data (consistent overall length)	PKW channel
	0xC0 0xD9 0xD9		26 words input/output data (consistent overall length)	
	0xF3 0xC0 0xD9 0xD9		26 words input/output data (consistent overall length)	PKW channel
	0xC0 0xDD 0xDD		30 words input/output data (consistent overall length)	
	0xF3 0xC0 0xDD 0xDD		30 words input/output data (consistent overall length)	PKW channel

3.1.3 PKW parameter channel

Some PPOs offer an additional cyclic parameter channel. This channel allows drive parameters to the read and written.

Table 3.9 PKE parameter identification

PKW							
1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
PKE (1 word)		IND (1 word)		PKW1 (1 word)		PKW 2 (1 word)	

The parameter consists of a total of 4 words: the parameter identifier PKE (1 word), the sub-index IND (1 word) and the parameter identification word, which occupies the data area PKW1 (1 word) to PKW2 (1 word). The parameter identification is shown by bits in the following table.

AK				PNU											
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0

AK	Request or reply identification (value range 0..15)
PNU	Parameter number (value range 1...4095)

The following tables list the request identification (master) and the reply identification (slave).

Table 3.10 Request identification AK (master ⇨ slave)

Auftragskennung	Funktion
0	No request
1	Request parameter value
2	Change parameter value (word)
3	Change parameter value (double word)
4	Read parameter description
5	-
6	Request parameter value (array)
7	Change parameter value (array) (word)
8	Change parameter value (array) (double word)

Table 3.11 Reply identification AK (Slave ⇨ Master)

Reply identification	Function
0	No reply
1	Parameter value sent (word)
2	Parameter value sent (double word)
3	Parameter description sent
4	Parameter value (array) sent (word)
5	Parameter value (array) sent (double word)
6	-
7	Request not executable, see error no.

On reply identification 7 the error number sent to the drive from the master is shown in the area PKW1 to PKW2. The following table lists these error numbers.

Table 3.12 Reply identification AK (Slave ⇨ Master)

Error	Statement
0	Impermissible PNU
1	Parameter cannot be changed
2	Lower or upper parameter value limit transgressed
3	Defective sub-index
4	Not an array
5	Incorrect data type
...	
17	Request cannot be executed because of the operating status
18	Other error

In addition request identification 4 can be used to read a parameter description. The parameter description receives relevant information regarding the respective parameter. The following table shows the sub-indexes that can be used to access the individual parameter structure elements. The sub-index is indicated only by byte 3.

Table 3.13 Parameter description

Sub-index	Meaning	Data type
1	Identifier (ID)	V2
2	Number of field elements or string length	Unsigned 16
3	Standardisation factor	Floating Point
4	Variable attributes	OctetString 2
5	Reserved	OctetString 4
6	Name (only the first four bytes are sent)	VisibleString 16
7	Lower limit value	OctetString 4
8	Upper limit value	OctetString 4
9	Reserved	OctetString 2
10	ID extension	extension V2
11	PZD reference parameter	Unsigned 16
12	PZD standardisation	V2

The identifier (sub-index 1) in the parameter description identifies additional characteristics of the respective parameter. Table 3-8 describes the meaning of the identifier.

Table 3.14 Structure of the identifier

Bit	Meaning	Explanation
15	Reserved	
14	Array	
13	Parameter value can only be reset	If this bit is set, the respective parameter value can be varied externally only so as to be set to zero
12	Parameter value was changed to a value different from the factory settings	If this bit is set, the parameter value is different from the factory settings
11	Reserved	
10	Additional text array can be called up	
9	Parameter cannot be written	
8	Standardisation factor and variable attributes not relevant	This bit is set if the parameter is of a data type that cannot be used to calculate any physical values (e.g. data type string)
0 - 7	Data type of the parameter value (value = "Profi-Drive table 9")	

Table 3.15 Master control word

Bit	Operating mode: Speed Control	Operating mode: Positioning control
Bit 15 (MSB)		
0	Apply relative positioning immediately after start enable	
1	Speed mode	
Bit 14		
0	Normal positioning	
1	Speed mode	
Bit 13		
0	Not used	New reference values activated by toggling the master control word bit 6
1	Not used	New reference values are loaded directly
Bit 12		
0	Not used	Positioning reference value = absolute
1	Not used	Positioning reference value = relative
Bit 11		
0	Not used	Stop homing run
1	Not used	Start homing run
Bit 10		
0	No access rights over the PLC	
1	Access rights over the PLC	
Bit 9		
0	Jog mode 2 off	Jog mode 2 off
1	Jog mode 2 on	Jog mode 2 on
Bit 8		
0	Jog mode 2 off	Jog mode 1 off
1	Jog mode 1 on	Jog mode 1 on
Bit 7		
0 1	Error acknowledgement at rising flank 0 ⇨ 1	

Table 3.15 Master control word, prosecution

Bit	Operating mode: Speed Control	Operating mode: Positioning control
Bit 6		
0 1	Deactivate reference value Activate reference value	Activate positioning set at rising and falling flank (0 ⇨ 1 und 1 ⇨ 0)
Bit 5		
0	Freeze ramp generator	No feed hold
1	Unfreeze ramp generator	Feed hold
Bit 4		
0	Reset ramp generator	Interrupt positioning set
1	Activate ramp generator	Do not interrupt positioning set
Bit 3		
0	Controller not enabled	
1	Controller enabled (operation enabled)	
Bit 2		
0	Quick stop active	
1	Quick stop inactive	
Bit 1		
0	Spin out of true active	
1	Spin out of true inactive	
Bit 0		
0	Switch off power stage (OFF)	
1	Switch on power stage (ON)	
11		Start Homing Procedure / Stop Homing Procedure
12		Relative positioning
13		Immediate start on changing the position, speed or the acceleration
14		Speed mode
15		Apply relative positioning immediately after start enable

Using parameter COM_DP_CtrlConfig bits 6 and 8 can be configured:

Table 3.16 Master control word

Bit number	Value = 0 (Default-value)	Value = 1
	The positioning task can be started with the negative and positive flank (profile 4.0).	The positioning task can only be started with the positive flank (profile 4.1).
	The jog mode is manufacturerspecific	The jog mode behaves as described in profile 4.1.

3.2.1 Jog mode speed mode

Bit 8 and 9 of the control word provide a jog mode in the speed mode:
If bit 8 of the parameter COM_DP_CtrlConfig is set to 0, the drive behaves as follows (jog mode manufacturer-specific):

- If bit 8 is set to 1, the drive applies the speed that is given in parameter COM_DP_RefJogSpeed1.
- If bit 9 is also set to 1, the value in the parameter COM_DP_RefJogSpeed2 is used as the reference value.
- If bit 9 is set to 0 again, COM_DP_RefJogSpeed1 is used as the reference again.
- If bit 8 is set to 0, while bit 9 is still set to 1, there is no change
- If bit 9 is set to 1, the drive applies the negated speed that is given in parameter COM_DP_RefJogSpeed1. The direction of rotation is therefore inverted.
- If bit 8 is also set to 1, the negated value in the parameter COM_DP_RefJogSpeed2 is used as the reference value.
- If bit 8 is set to 0 again, -COM_DP_RefJogSpeed1 is used as the reference again.
- If bit 9 is set to 0, while bit 8 is still set to 1, there is no change
- In case of negative reference values, a negated speed is positive again.
- The jog mode can only be activated if the motor is at standstill.
- If bit 8 of the parameter COM_DP_CtrlConfig is set to 1, the drive behaves in accordance with the profile (profile 4.1), page 84 [13]:
- The jog mode can only be activated if the motor is at standstill.
- Bits 4 to 6 of the control word are 0.
- If bit 8 is set to 1, the drive applies the speed that is given in parameter COM_DP_RefJogSpeed1.
- If bit 8 and 9 are set, there is no change, the old reference value is retained.

3.2.2 Jog mode positioning mode

The jog mode for the positioning mode behaves as for the speed mode. Bit 4 and 5 of the control word must be set.

3.2.3 Jog mode reference value parameter

- The parameters COM_DP_RefJogSpeed1 and COM_DP_RefJogSpeed2 are of type Int32 and can be mapped as process data.

Table 3.17 Master control word 2

Bit number	Value = 1
Bit 0 - 11	Not used
Bit 12 - 15	Master sign of life

If no synchronous application is implemented, the master sign of life need not be transmitted, allowing the entire second status word to be freely assigned.

3.3 Drive status word

Table 3.18 Drive status word

	Operating mode: Speed Control	Operating mode: Positioning control
Bit 15 (MSB)	Not used	
Bit 14		
0	„ENPO" or „Safe Standstill" not set	
1	„ENPO" or „Safe Standstill" set	
Bit 13		
0	Drive rotating	
1	Drive stationary	
Bit 12		
0	Not used	Motion request confirmation by toggling this bit
1	Not used	
Bit 11		
0	Not used	Homing point not yet set
1	Not used	Homing point set
Bit 10		
0	Frequency or speed not reached	Target position not reached
1	Frequency or speed reached or exceeded	Target position reached
Bit 9		
0	No access rights over the PLC	
1	Access rights over the PLC granted	
Bit 8		
0	Speed error outside the tolerance band	Positioning slippage error outside the tolerance band
1	Speed error within the tolerance band	Positioning slippage error within the tolerance band
Bit 7		
0	No warning	
1	Warning registered	
Bit 6		
0	Switch on not prevented	
1	Switch on prevented	
Bit 5		
0	Quick stop activated	
1	Quick stop deactivated	

Table 3.18 Drive status word, prosecution

	Operating mode: Speed Control	Operating mode: Positioning control
Bit 4		
0	Spin out of true activated	
1	Spin out of true deactivated	
Bit 3		
0	No error	
1	Error reported	
Bit 2		
0	Control blocked	
1	Control active (in operation / drive responding to reference values)	
Bit 1		
0	Power stage inactive (not ready)	
1	Power stage active (ready)	
Bit 0		
0	Not ready to start	
1	Ready to start	

Table 3.19 Drive status word 2

Bit	Meaning
0-1	Profile generator status 0: Stop 1: Acceleration 2: Positioning with allowable speed 3: Delay
2	Torque limitation with positive direction of travel
3	Torque limitation with negative direction of travel
4	ISD00
5	ISD01
6	ISD02
7	ISD03
8	Reserved
9	Reserved
10	Reserved
11	Reserved
12-15	Reserved for Profidrive

If no synchronous application is implemented, the slave sign of life need not be transmitted, allowing the entire second status word to be freely assigned.

Figure 3.2 GeneralSystem status machine (control via PROFIBUS)

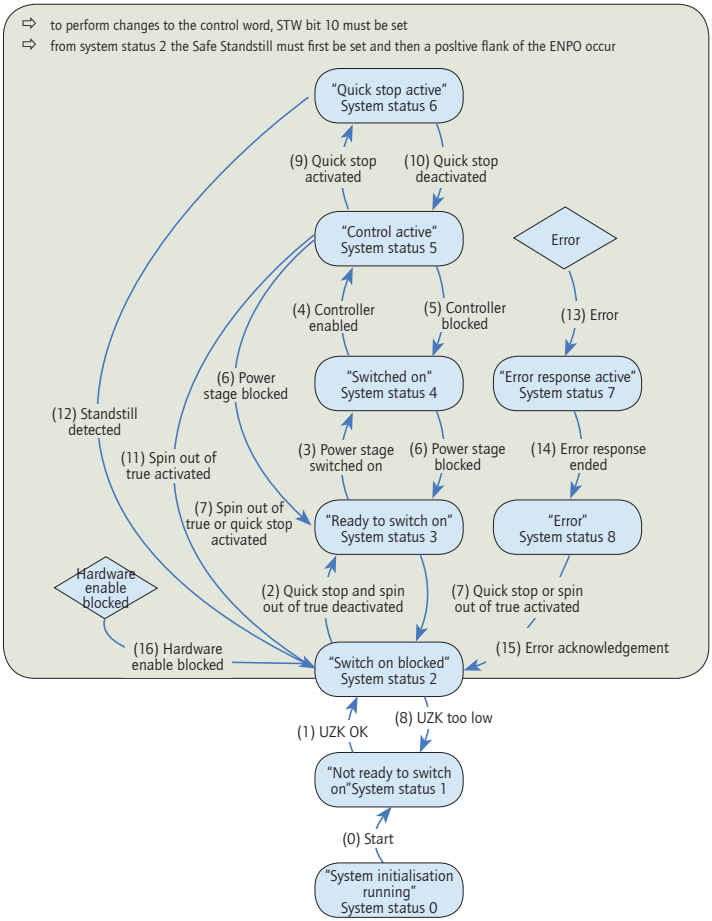

to perform changes to the control word, STW bit 10 must be set
from system status 2 the Safe Standstill must first be set and then a posltive flank of the ENPO occur
"Quick stop active"
System status 6
(9) Quick stop activated
(10) Quick stop deactivated
"Control active"
System status 5
Error
(4) Controller enabled
(5) Controller blocked
(13) Error
(6) Power stage blocked
"Switched on"
System status 4
"Error response active"
System status 7
(12) Standstill detected
(11) Spin out of true activated
(3) Power stage switched on
(6) Power stage blocked
(14) Error response ended
(7) Spin out of true or quick stop activated
"Ready to switch on"
System status 3
"Error"
System status 8
Hardware enable blocked
(2) Quick stop and spin out of true deactivated
(7) Quick stop or spin out of true activated
(16) Hardware enable blocked
"Switch on blocked"
System status 2
(15) Error acknowledgement
(1) UZK OK
(8) UZK too low
"Not ready to switch on"System status 1
(0) Start
"System initialisation running"
System status 0

Table 3.20 System statuses

System status	Designation	Description
0	System initialisation running (start)	Initialisation after device reset (e.g. hardware, parameter list, controller, ...)
1	Not ready to switch on	Initialisation completed, but no power supply, or intermediate circuit voltage less than switch-on threshold
2	Switch-on inhibit (switch on disabled)	Intermediate circuit voltage greater than switch-on threshold
3	Ready to switch on	Optional conditions satisfied (e.g. homing run, quick stop inactive ...)
4	Switched on	Power stage enabled
5	Operation enabled	Power supplied to motor, operation active
6	Quick stop active	Quick stop active*
7	Fault reaction active	Fault reaction is active, reference values from the PROFIBUS master are ignored.
8	Fault	Drive in fault condition, reference values from the PROFIBUS master are ignored.

- Quick stop can be triggered by various circumstances. The parameter 2218 (MP_QuickStopOC) allows the type of quick stop to be selected.

Table 3.21 Quickstop Option Code

Quickstop option code	Meaning
0	Disable drive function
1	Slow down on slow down ramp
2	Slow down on quick stop ramp
3	Slow down on the current limit
4	Slow down on the voltage limit
5	Slow down on slow down ramp and stay in „quick stop“
6	Slow down on quick stop ramp and stay in „quick stop“
7	Slow down on the current limit and stay in „quick stop“
8	Slow down on the voltage limit and stay in „quick stop“

Table 3.22 System status changeovers

System status changeover	Designation	Description
0	Start	Initialisation after boot-up completed
1	UZK OK	Intermediate circuit voltage greater than switchon threshold
2	Quick stop and spin out of true deactivated	Spin out of true deactivated ⇨ STW bit 1 = 1 Quick stop deactivated ⇨ STW bit 2 = 1
3	Power stage switched on	Power stage switched on ⇨ STW bit 0 = 1
4	Controller enabled	Controller enabled ⇨ STW bit 3 = 1
5	Control blocked	Control blocked ⇨ STW bit 3 = 0 *
6	Power stage blocked	Power stage blocked ⇨ STW bit 0 = 0
7	Quick stop or spin out of true activated	Spin out of true activated ⇨ STW bit 1 = 0 Quick stop activated ⇨ STW bit 2 = 0
8	UZK too low	Intermediate circuit voltage less than switch-on threshold
9	Quick stop activated	Activate quick stop ⇨ STW bit 2 = 0
10	Quick stop deactivated	Deactivate quick stop ⇨ STW bit 2 =1
11	Spin out of true activated	Activate spin out of true ⇨ STW bit 1 = 0
12	Standstill detected	Standstill was detected
13	Fault	Fault event occurred (can occur in any system status)
14	Fault reaction ended	Fault reaction has ended (e.g. fault stop ramp)
15	Fault acknowledgement	Acknowledgement of the reported fault ⇨ STW bit 7 = 1 or by a rising flank of the power stage enable
16	Power stage blocked	Power stage blocked (can occur in any system status)

* Parameter 144 (Autostart) determines whether the control of the operation enable is flank-triggered (0) or status-dependent (1) erfolgt [Parameter List ⇨ Motion Profile ⇨ Basic Settings].

4. Acyclic data transmission – DPV1

4.1 Telegram type SD2 used for DPV1 services

In addition to DPV0 cyclic data communications, which are intended as standard for quick updates of I/O process data, DPV1 acyclic services are available as one-off events. They offer the facility for instance to read or write parameters acyclically and thus without interfering with cyclic data traffic. Telegram type SD2 in accordance with the following table is used for the DPV1 PROFIBUS DP extension.

Table 4.1 PROFIBUS SD2 telegram for DPV1 services

SD	LE	LEr	SD	DA	SA	DSAP	SSAP	DU	FCS	ED
Start Delimiter	Length	Length repeat	Start Delimiter	Destination Address	Source Address	Destination Service Access Point	Source Service Access Point	Data Unit	Frame Check Sequence	End Delimiter
68H	X	X	68H	xx	xx	xx	xx	X..		

The acyclic services can be used equally well by a class 1 master (PLC etc.) and by a class 2 master (PC tool). The following table gives and overview of the acyclic services available in relation to the respective master class.

Table 4.2 An overview of the acyclic services offered

Azyklische Dienste	Master-Klasse	Bedeutung	DSAP	SSAP
Initiate request	2	Establish an acyclic connection	32H	31H
Abort request	2	Break off an acyclic connection	32H	0..30H
Read request	2	Read request via DPV1	32H	0..30H
Write request	2	Write request via DPV1	32H	0..30H
Data request	2	Data transfer	32H	0..30H
Read request	1	Read request via DPV1	33	33H
Write request	1	Write request via DPV1	33	33H
Alarm	1	Alarm handling	33	33H

The access mechanism on DPV1 is always performed according to a fixed layout

1. Write request (5F)										
SD	..	DSAP	SSAP	DU Req. id	DU Slot	DU Index	DU Length	DU User	FCS	ED
68H	xx	32	30	5F	0	2F	n+1	0..n	xx	16H

2. Write reply (5F)									
SD	..	DSAP	SSAP	DU Req. id	DU Slot	DU Index	DU Length	FCS	ED
68H	xx	32	30	5F	0	2F	n+1	xx	16H

3. Read request (5E)									
SD	..	DSAP	SSAP	DU Req. id	DU Slot	DU Index	DU Length	FCS	ED
68H	xx	32	30	5E	0	2F	MAX	xx	16H

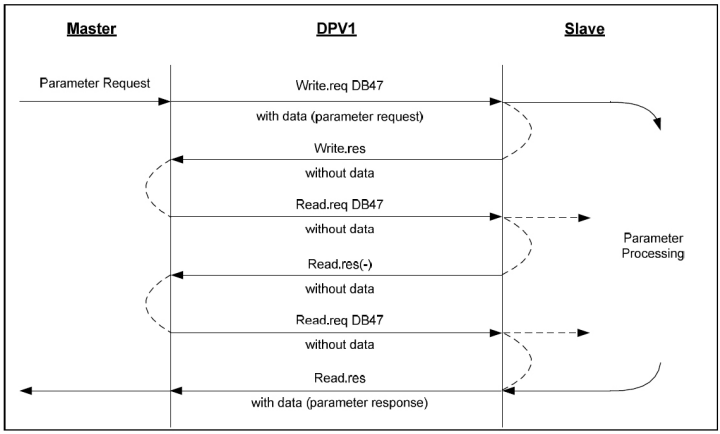
4. Read reply (5E)										
SD	..	DSAP	SSAP	DU Req. id	DU Slot	DU Index	DU Length	DU User	FCS	ED
68H	xx	32	30	5E	0	2F	n+1	0..n	Xx	16H

Each read or write access must first be initiated by a write service on Data Unit Index 47 (2Fhex) (1). This write request gives the slave the information about the request it should execute. After this the slave acknowledges with a reply telegram (2), which initially contains no reply data.

This is simply an acknowledgement of the request and contains only the mirrored DPV1 header of the request telegram. In the event of an error, a negative reply is sent. To then read the data from the slave, the master must present a read request (3). If the reply (4) to this is positive, the user data can be used by the master. In the event of an error, a negative reply is sent. Figure “DPV1 Read Request” shows the telegram sequence for a read access. This shows the slave sending a negative read reply to the first read request. This negative read reply means that the required data cannot yet be provided.

Not until the following cycle has the slave executed the request to the extent that it can send a positive read reply with the requested data.

Figure 4.1 DPV1 Read request



This transmission format is in "Big Endian" (Motorola, the highest byte is transmitted first).

Word format	
0. Byte	1. Byte
High Byte	Low Byte

Double word format			
0. byte	1. byte	2. byte	3. byte
High byte High word	Low byte High word	High byte Low word	Low byte Low word

The data unit in the table "PROFIBUS SD2 telegram for DPV1 services" of telegram type SD2 can be split into five areas:

- **Req.id (1 byte)**
  This is the function number of the DPV1 service. This describes for instance whether a parameter should be read or should be written. More detailed information can be found in the table "Assignment of the Data Unit".
- **Slot (1 byte)**
  DPV1 slaves consist of a number of physical or virtual slots. The drive is triggered by addressing a slot, following which the slot address is not evaluated.
- **Index (1 byte)**
  The index contains the address of the data area in which the slave makes available the data for a parameter access. In accordance with ProfiDrive this is specified with the fixed data area number 47.
- **Length (1 byte)**
  Gives the length of the user data that follow. In the case of a read access, the length must be sufficiently large for the data to be read (max. 240 byte) User (1 byte...n byte) Contains the user data to be processed

Table 4.3 Assignment of the data unit

Data Unit (DU) byte	Data Unit Param	Value	Meaning	
0	Req.id	48H	Idle REQ, RES	Idle REQ, RESP
		51H	Data Transport REQ, RES	Data transport REQ, RESP
RESP				
		56H	Resource Manager, REQ	Resource manager REQ
		57H	Initiate REQ, RES	Initiate REQ, RESP
		58H	Abort REQ	Abort REQ
		5CH	Alarm REQ, RES	Alarm REQ, RESP
		5EH	Read REQ, RES	Read REQ, RESP
		5FH	Write REQ, RES	Write REQ, RESP
		D1H	Data Transport NEG RES	Data transport RESP
		D7H	Initiate NEG RES	Initiate negative RESP
		DCH	Alarm NEG RES	Interrupt negative RESP
		DEH	Read NEG RES	Read negative RESP
		DFH	Write NEG RES	Write negative RESP
1	Slot	00H..FEH	Slot number	
2	Index	2FH	Index	
3	Length	xx	Length of the user data (max 240 bytes)	
4..n	UserData	xx	User data	
[Alarms are not currently supported]				

In the following table the telegram format for the user data (Data Unit User Data) for a DPV1 parameter request and a DPV1 parameter reply are shown.

Table 4.4 Assignment of the data unit

DPV1 Parameter Request			Byte address
Request Header	Request reference	Request identification	0
	Axis No	No. of Parameters (n)	2
1. Parameter adress	Attribute	No. of elements	3
	Paramter Number (PNU)		
	Subindex		
n. Parameter adress	.....		4+6*(n-1)
	Format	No. of values	4+6*n
	Values		
	...		
	... ...		
			4+6*n +...+ (format_n *amount_n)

Table 4.5 DPV1 Parameter reply

DPV1 Parameter Reply			Byte address
Reply header	Request reference (mirror)	Response identification	0
	Axis No (mirror)	No. of Parameters (n)	2
1. Parameter address	Format	No. of values	4
	Value / error code		
	...		
No. of parameter address	... ...		
			4+...+ (format_n *amount_n)

The user data are structured as follows:

- **Request reference:**
  The Request Reference is specified by the master and mirrored back by the slave in the reply telegram. Based on this reference the master can uniquely assign each reply telegram to a request telegram. A master changes the request reference with each new request.
- **Request ID**
  This identifier has essentially the task of describing the type of parameter treatment. Currently two different identifiers are defined:
  - Requesting for a parameter
  - Changing a parameter
  Further details on identifiers can be found in the table “User data”.
- **Response ID**
  This identifier contains information on the origin of a request. If a request is executed correctly, the response ID matches the request ID. If a request cannot be executed, an identifier in accordance with table “User data” is generated.
- **Axis No.**
  This value allows an individual axis in a multi-axis system to be addressed selectively. (Axis No. ⇨ 0 single axis).
- **No. of Parameters**
  Number of parameters that are processed in a request.
- **Attributes**
  Describes the individual access to a parameter structure. For instance whether one may access the actual numerical value or use the parameter description text. Further information can be found in the table “User data”.
- **Number of Elements**
  When accessing an array or a string, this area contains the filed size or the string length.
- **Parameter Number**
  Contains the parameter number (PNU).
- **Subindex**
  Addresses the first array element of a parameter or the beginning of a character string. This also allows access to descriptive texts and text arrays.
- **Format**
  Specifies the respective parameter and ensures a unique assignment of the parameter value in the telegram.
- **Number of values**
  Number of following values.
- **Values**
  Parameter values

Table 4.6 User data

Field name	Data type	Value	Meaning	Comments
Request reference	Unsigned8	0x00 0x01..0xFF	Reserved	
Request ID	Unsigned8	0x00 0x01 0x02 0x03..0x03F 0x40..0x7F 0x80..0xFF	Reserved Request parameter Change Parameter Reserved Manufacturer-specific Reserved	
Response ID	Unsigned8	0x00 0x01 0x02 0x03..0x3F 0x40..0x7F 0x80 0x81 0x82 0x83..0xBF 0xC0..0xFF	Reserved Request parameter (+) Change Parameter (+) Reserved Manufacturer-specific Reserved Request parameter (-) Change Parameter (-) Reserved Manufacturer-specific	
Axis No	Unsigned8	0x00 0x01..0xFE 0xFF	Device Representative Axis-Number 1..254 Reserved	Zero = single axis
No. of Parameters	Unsigned8	0x00 0x01..0x27 0x28..0xFF	Reserved Quantity 1..39 Reserved	Limited by DPV1 telegram length
Attribute	Unsigned8	0x00 0x10 0x20 0x30 0x40..0x70 0x80..0xF0	Reserved Value Description Text Reserved Manufacturer-specific	
No. of Elements	Unsigned8	0x00 0x01..0xEA 0xEB..0xFF	Special Function Quantity 1..234 Reserved	Limited by DPV1 telegram length
Parameter Number	Unsigned16	0x0000 0x0001... 0xFFFF	Reserved Number 1..65535	
Subindex	Unsigned16	0x0000... 0xFFFF	Number 1..65535	
Format	Unsigned8	0x00 0x01..0x36 0x37..0x3F 0x40 0x41 0x42 0x43 0x44 0x45..0xFF	Reserved Data Types Reserved Zero Byte Word Double Word Error Reserved	
No. of Values	Unsigned8	0x00..0xEA 0xEB..0xFF	Quantity 0..234 Reserved	Limited by DPV1 telegram length
Error Number	Unsigned16	0x0000... 0x00FF	Error Numbers (see table below)	

Table 4.7 Error number

Error number	Meaning
0x00	Impermissible parameter number
0x01	Parameter value cannot be changed
0x02	Value area of the parameter transgressed
0x03	Defective parameter sub-index
0x04	Parameter is not an array
0x05	Incorrect parameter data type
0x06	Change access with value not equal to zero which is not permitted
0x07	Change access on a descriptive element, which cannot be changed
0x09	No descriptive text available
0x11	Request cannot be performed in the present system status
0x14	Impermissible value
0x15	Reply telegram is too long
0x16	Impermissible parameter address
0x17	Illegal format
0x18	Number of parameter values is inconsistent
0x19	Request is for an non-existent axis

4.2 Examples of request and reply telegrams

Table 4.8 ID:2 Change Parameter, Attr. 0x10: Value; Pnu = 918 = 0x396, Format word=0x42

Write word													
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low	Sub high	Sub low	Format	No. Values	Value high	Value Low
0	2	0	1	0x10	0..1	3	0x96	0	0	0x42	1	0	7

Table 4.9 ID:2 Change Parameter

Positive reply			
Refer.	Req. ID	Axis	No. Param.
0	2	0	1

- Parameter 918 now has the value 7

Table 4.10 ID:2 Change Parameter, Attr. 0x10: Value; Pnu = 918 = 0x396, Format word=0x42

Write double word							
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low
0	2	0	1	0x10	0..1	4	0xFA
Sub high	Sub low	Format	No. Values	Value high	Value Low	Value l high	Value l low
0	0	0x43	1	1	2	3	4

Table 4.11 ID:2 Change Parameter

Refer.	Req. ID	Axis	No. Param.
0	2	0	1

- Parameter 884 now has the value 16909060

Read simple parameter value

Table 4.12 ID:1 Request Parameter, Attr. 0x10: Value; Pnu = 922 = 0x39A

Read word									
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low	Sub high	Sub low
0	1	0	1	0x10	0..1	3	0x9A	0	0

Table 4.13 Format word=0x42; Parameter value = 9

Positive reply							
Refer.	Req. ID	Axis	No. Param.	Format	No values	Value high	Value low
0	1	0	1	0x42	1	0	9

Table 4.14 ID:1 Request Parameter, Attr. 0x10: Value; Pnu = 922 = 0x39A

Read double word									
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low	Sub high	Sub low
0	1	0	1	0x10	0..1	4	0xFA	0	0

Table 4.15 Format dword=0x43; Parameter value = 0x01020304 = 16909060

Positive reply									
Refer.	Req. ID	Axis	No. Param.	Format	No values	Value H high	Value H Low	Value l high	Value l low
0	1	0	1	0x43					

Defective accesses

Table 4.16 ID:1 Request Parameter, Attr. 0x10: Value; Pnu = 9

Defective parameter numbers									
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low	Sub high	Sub low
0	1	0	1	0x10	0..1	0	9	0	0

Negative reply

Table 4.17 Format error=0x44; Parameter value = 0 = incorrect parameter number

Refer.	Req. ID	Axis	No. Param.	Format	No values	Value high	Value low
0	0x81	0	1	0x44	1	0	0

Write parameter values array

Table 4.18 ID:2 Change Parameter, Attr. 0x10: Value; Pnu = 918 = 0x396, Format word=0x42

Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Pnu high	Pnu Low	Sub high	Sub low
0	2	0	1	0x10	5	3	0x93	0	0

Format	No. Values	Value 0 high	Value 0 Low	-	Value 4 high	Value 4 low
0x42	5	3	C7		0	0

- Parameter values = 0x03C7, 0x04F6, 0x04F6, 0x04F6, 0

OK reply

Refer.	Req. ID	Axis	No. Param.
0	2	0	1

- Parameter 915 now contains the entries for the parameter values.
- No standard telegram smaller than 10 is set up in the device, since then it could not be overwritten. Use remedy PPO5.

Read parameter values array

Table 4.19 ID:1 Attr. : 0x10 Pnu = 915=0x393

Zugeordnete Prozessdaten Sollwerte lesen									
Refer.	Req. ID	Axis	No. Param.	Attr.	No. Ele.	Value 0 high	Value 0 Low	Value 4 high	Value 4 low
0	2	0	1	0x10	5	3	C7	0	0

OK reply

Table 4.20 ID: 1 Format: 0x42

Refer.	Req. ID	Axis	No. Param.	Format	No Values	Value 0 high	Value 0 low	Value 1 high	Value 1 Low
0	1	0	1	0x42	5	3	0xC7	4	0xF6

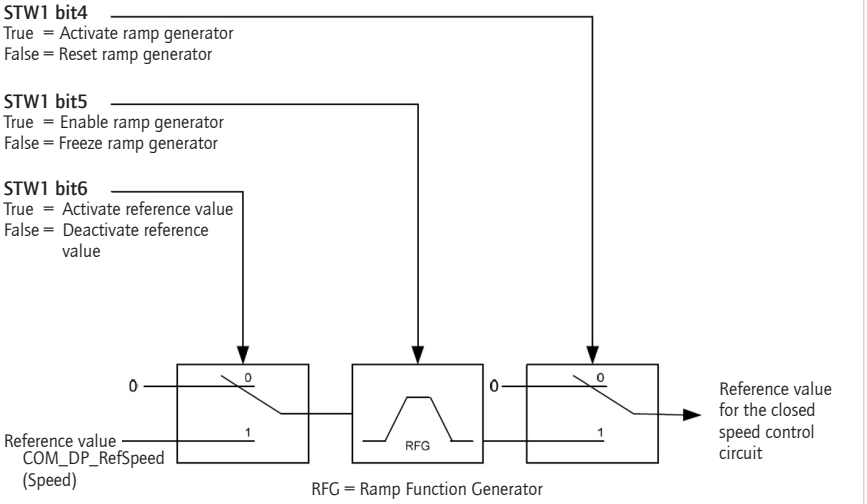
Value 2 high	Value 2 Low	Value 3 high	Value 3 Low	Value 4 high	Value 4 low
4	0xF6	5	0	0	0

5. Operating modes

5.1 Speed Control

In speed control mode the speed control reference value can be influenced using 3 bits in the master control word (3.2).

Figure 5.1 Speed control



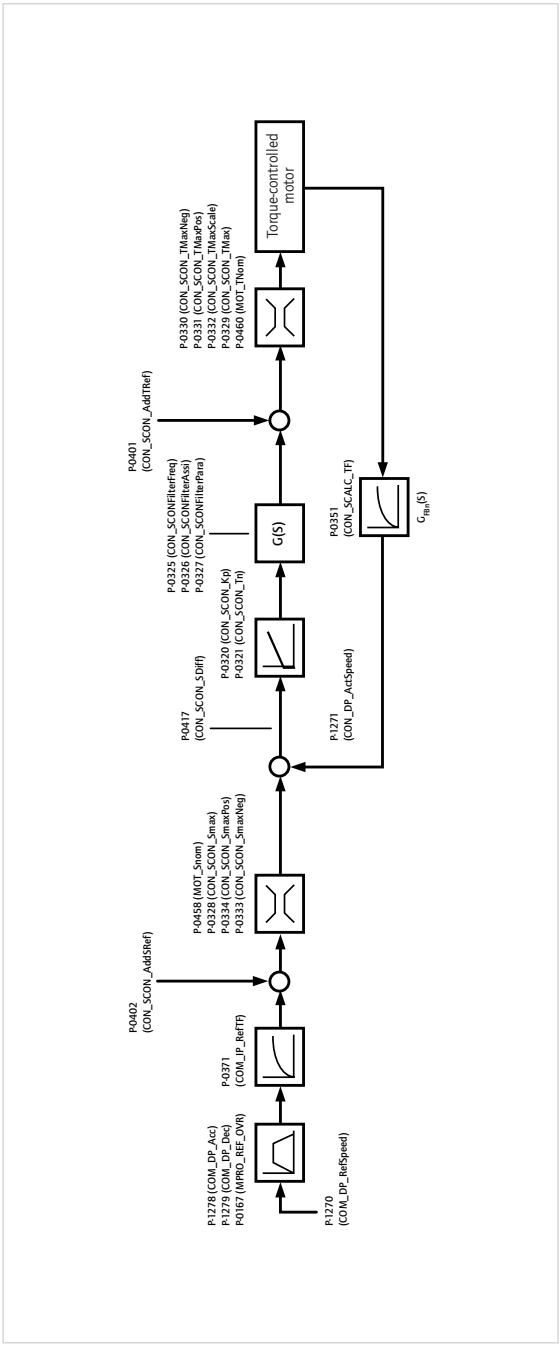
Setting the control word bit 4 allows the speed reference value to be taken over by the ramp generator. The control word bit 5 releases the ramp generator; resetting it freezes the ramp generator again. The input of the ramp generator is influenced by the control word bit 6. If bit 6 is set, the reference value is forwarded. If bit 6 is not set, the reference value zero is forwarded.

5.2 Speed control circuit and associated control parameters

Table 5.1 Speed control circuit

P-no.:	Parameter name	Meaning
P-1270	COM_DP_RefSpeed	Speed reference value
P-1278	COM_DP_Acc	Acceleration ramp
P-1279	COM_DP_Dec	Deceleration ramp
P-0167	MPRO_REF_OVR	Speed override
P-0371	CON_IP_RefTF	Filter time constant speed reference value
P-0402	CON_SCON_AddSRef	Additive speed reference value
P-0458	MOT_Snom	Nominal speed of motor
P-0328	CON_SCON_SMax	Speed limitation (reference value: nominal speed of motor)
P-0334	CON_SCON_SMaxPos	Positive speed limitation (reference value: nominal speed of motor)
P-0333	CON_SCON_SMaxNeg	Negative speed limitation (reference value: nominal speed of motor)
P-0417	CON_SCON_SDiff	Speed controller differential
P-1271	COM_DP_ActSpeed	Actual speed
P-0320	CON_SCON_Kp	PI speed controller amplification
P-0321	CON_SCON_Tn	PI_speed controller lag time
P-0325	CON_SCONFilterFreq	Limit frequencies for torque reference value filter
P-0326	CON_SCONFilterAssi	Torque reference value filter draft parameter
P-0327	CON_SCONFilterPara	Torque reference value filter parameter
P-0351	CON_SCALC_TF	Actual speed filter time constant
P-0401	CON_SCON_AddTRef	Additive torque reference value
P-0330	CON_SCON_TMaxNeg	Negative torque limitation (reference value: nominal torque)
P-0331	CON_SCON_TMaxPos	Positive torque limitation (reference value: nominal torque)
P-0332	CON_SCON_TMaxScale	Torque scaling factor
P-0339	CON_SCON_Tmax	Torque limitation (reference value: nominal torque)
P-0460	MOT_TNom	Motor nominal torque

Figure 5.2 Speed control circuit



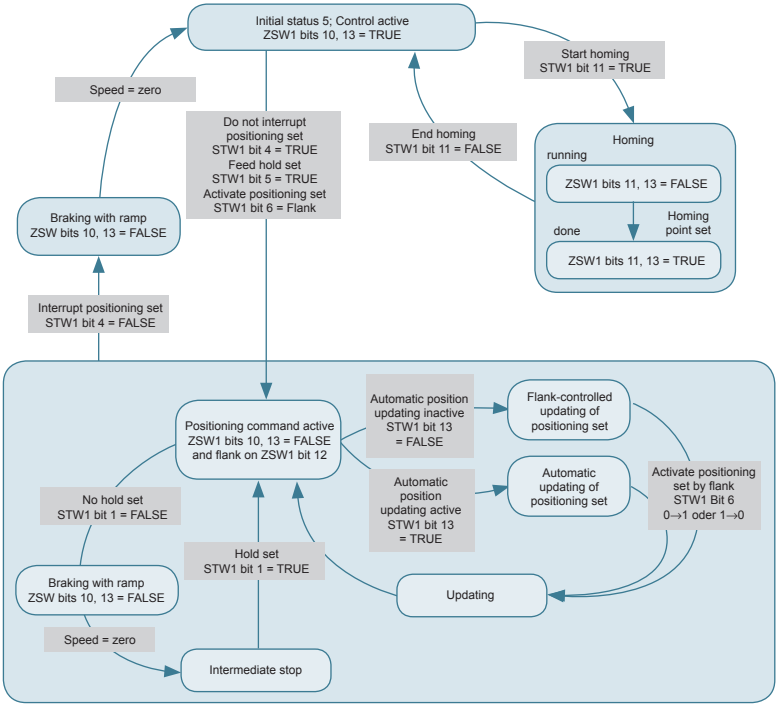
5.3 Position control

In position control operating mode, based on operating status 5 (see section 3.4) the drive can change over into various statuses in response to defined bits in the master control word (3.2). These statuses are explained in Figure 5-2.
A positioning command is activated if the control word bit 4, the feed hold is set via bit 5 and a flank is set on control word bit 6. Further positioning commands can then be activated via the control word bit 13.
If bit 13 is set, changes to the reference position, positioning speed or positioning acceleration lead directly to a new movement request. If bit 13 is not set, a new movement request is activated only by means of a positive or negative flank of control word bit 6.

If bit 6 is set in parameter 1267 (COM_DP_CtrlConfig), the positioning task is only activated on the positive flank. This corresponds to the last PROFIDrive profile 4.1. If the feed hold is reset whilst a movement command is active, the drive will be braked via a ramp to a standstill and is set to the status intermediate stop. The current movement request will not be executed until the feed hold is set again.

A movement request can be interrupted by resetting control word bit 4.
In this case the drive will also be braked to a standstill and set to the status “Control active”. In the initial status 5, additionally a homing run can be triggered by the control
word bit 11.

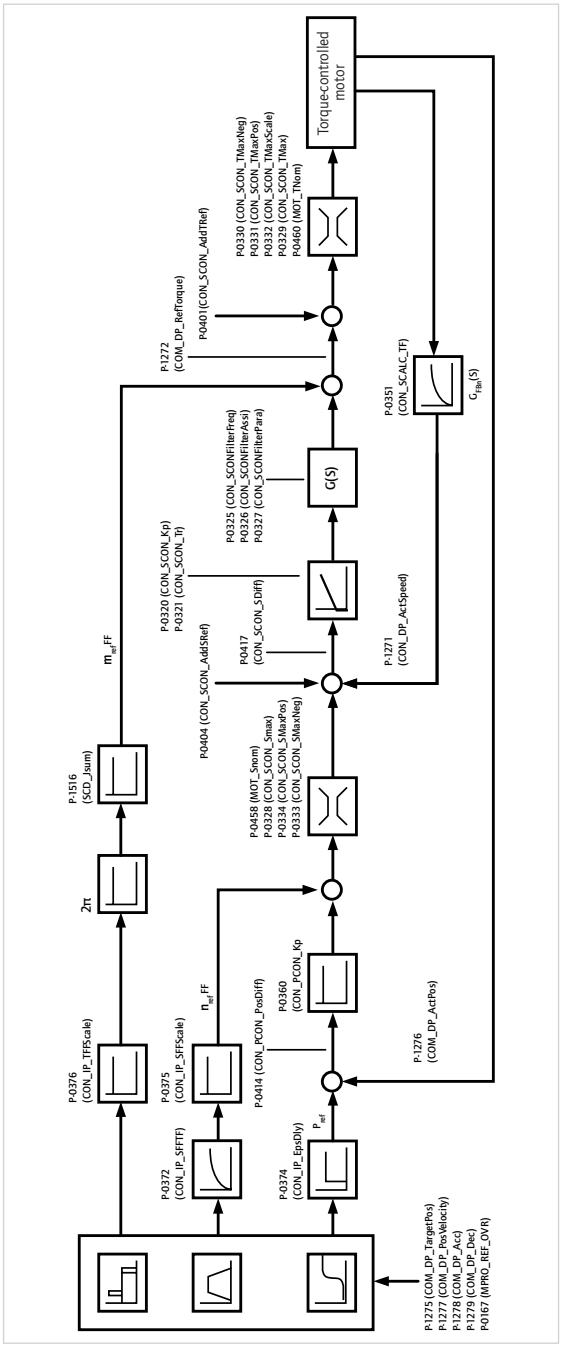
Figure 5.3 Position control



5.4 Control parameters

P-Nr.:	Parameter name	Meaning
P-1270	COM_DP_RefSpeed	Speed reference value
P-1278	COM_DP_Acc	Acceleration ramp
P-1279	COM_DP_Dec	Deceleration ramp
P-0167	MPRO_REF_OVR	Speed override
P-1276	COM_DP_ActPos1	Current actual position
P-0402	CON_SCON_AddSRef	Additive speed reference value
P-0458	MOT_Snom	Nominal speed of motor
P-0328	CON_SCON_Smax	Speed limitation
P-0334	CON_SCON_SMaxPos	Positive speed limitation (reference value: nominal speed of motor)
P-0333	CON_SCON_SMaxNeg	Negative speed limitation (reference value: nominal speed of motor)
P-0417	CON_SCON_SDiff	Speed controller differential
P-1271	COM_DP_ActSpeed	Actual speed
P-1516	SCD_Jsum	Overall moment of inertia
P-0376	CON_IP_TFFScale	Scaling for pre-control of acceleration
P-1275	COM_DP_TargetPos	Target position
P-1277	COM_DP_PosVelocity	Positioning speed
P-0374	CON_IP_EpsDly	Position reference delay
P-0320	CON_SCON_Kp	PI speed controller amplification
P-0321	CON_SCON_Tn	PI_speed controller lag time
P-0325	CON_SCONFilterFreq	Limit frequencies for torque reference value filter
P-0326	CON_SCONFilterAssi	Torque reference value filter parameter
P-0327	CON_SCONFilterPara	Torque reference value filter parameter
P-0351	CON_SCALC_TF	Actual speed filter time constant
P-0401	CON_SCON_AddTRef	Additive torque reference value
P-0330	CON_SCON_TMaxNeg	Negative torque limitation (reference value: nominal torque)
P-0331	CON_SCON_TMaxPos	Positive torque limitation (reference value: nominal torque)
P-0332	CON_SCON_TMaxScale	Torque scaling factor
P-0339	CON_SCON_Tmax	Torque limitation (reference value: nominal torque)
P-0460	MOT_TNom	Motor nominal torque
P-0372	CON_IP_SFFTF	Filter time constant speed pre-control
P-0375	CON_IP_SFFScale	Scaling for pre-control of speed
P-0414	CON_PCON_PosDiff	Position controller differential (tracking error)
P-0360	CON_PCON_Kp	Position controller amplification

Figure 5.4 Position control circuit



6. Homing

6.1 Homing runs performed by the drive

Since relative sensor systems are used, the drive must be homed, triggered by bit 11 in control word 1. As soon as this bit is set by the master, the drive performs a positioncontrolled homing run using an internal profile generator and determined by homing run speed, homing run acceleration and employing the strategy saved in the homing run method.

6.2 Homing run speed

The homing run speed is specified by parameter 2262 (MPRO_402_HomingSpeeds) in the parameter editor [Parameter list ⇨ Motion Profile ⇨ Homing]. The user has the facility here to specify two different homing run speeds.

1. SpeedSwitch = Speed when moving to the limit switch
2. SpeedZero = Speed when moving to the zero point

6.3 Homing run acceleration

The homing run acceleration is specified by parameter 2263 (MPRO_402_HomingAcc) in the parameter editor [Parameter list ⇨ Motion Profile ⇨ Homing].

6.4 Zeroing offset

Absolute encoders (such as SSI multiturn encoders) present a special case for the homing run, since they directly generate the absolute position reference. For homing using these encoders it follows that no movement is required and in some circumstances even no power to the drive. Furthermore, the zeroing offset must be determined. The type 5 is particularly suitable for this. A zeroing offset can be set using the parameter 525 (ENC_HomingOff) [Parameter list ⇨ Motion Profile ⇨ Homing].

6.5 Homing cams, limit switches

The signal for the homing cams can optionally be linked to one of the digital inputs, for which the inputs ISD00 to ISD06 are available. When homing to the limit switches, the digital input must be selected as a positive limit switch using selection parameter LCW(5) or a negative limit switch using selection parameter LCW(6). When homing to cams, the parameter HOMSW(10) must be selected. (see parameter P 0101–P 0107).

The signal for the homing cams can optionally be linked to one of the digital inputs, for which the inputs ISD00 to ISD06 are available. Furthermore the limit switches can also be used for homing. The assignment of the digital inputs can be found under the parameter 101 to 107 [Parameter list ⇨ I/O configuration ⇨ Digital inputs]. When homing to the limit switches, the digital input must be selected as a positive limit switch using selection parameter LCW(5) or a negative limit switch using selection parameter LCW(6).
When homing to cams, the parameter HOMSW(10) must be selected.
The following table shows the necessary assignment of the digital inputs for the respective homing run methods.

Table 6.1 Homing run methods

P.-No.	Parameter identifier/ Setting	Identifier at DM 5	Function
P 2261		MPRO_402_HomingMethod	Digital inputs
(-7)	-	move pos. direction, for distance coded encoder	Homing run type for distance-coded encoder for positive direction
(-6)	-	move pos. direction, for distance coded encoder	Homing run type for distance-coded encoder for negative direction
(-5)	-	Act. position + homing offset (multiturn-encoder)	Homing (absolute encoder)
(-4)	HOMSW	Homing mode type 22 with continuous reference	Homing in progress, negative flank of the homing cam
(-3)	HOMSW	Homing mode type 20 with continuous reference	Homing in progress, positive flank of the homing cam
(-2)	-	No homing mode (act. position + homing offset)	No homing run; positioning is only by offset
(-1)	-	Reference position = homing offset (parameter HOOFF)	Current position=Zero
(0)	-	Not defined	No homing run
(1)	LCCW	Neg. end switch, zero pulse	Homing run negative limit switch and zero impuls
(2)	LCW	Pos. end switch, zero pulse	Homing run positive limit switch and zero impuls
(3)	HOMSW	Pos. reference cams, zero pulse at RefNock = Low	Homing run to cams, negative flank, positive direction of trave + zero impuls
(4)	HOMSW	Pos. reference cams, zero pulse at RefNock = High	Homing run to cams, positive flank, positive direction of trave + zero impuls
(5)	HOMSW	Neg. reference cams, zero pulse at RefNock = Low	Homing run to cams, negative flank, negative direction of trave + zero impuls
(6)	HOMSW	Neg. reference cams, zero pulse at RefNock = High	Homing run to cams, positive flank, negative direction of trave + zero impuls
(7) bis (14)	HOMSW	Left reference cam polarity, zero pulse at RefNock = Low	Various homing runs to cams
(15), (16)	-	not defined	Reserved
(17)	LCCW	Neg. end switch	Homing run negative limit switch

Tabelle 6.1 Homing run methods, prosecution

P.-No.	Parameter identifier/ Setting	Identifier at DM 5	Function
(18)	LCW	Pos. end switch	Homing run positive limit switch
(19)	HOMSW	Pos. reference cams, Stop at RefNock = Low	Homing run to cams, negative flank,positive direction of travel
(20)	HOMSW	Pos. reference cams, Stop at RefNock = High	Homing run to cams, positive flank,positive direction of travel
(21)	HOMSW	Neg. reference cams, Stop at RefNock = Low	Homing run to cams, negative flank,negative direction of travel
(22)	HOMSW	Neg. reference cams, Stop at RefNock = High	Homing run to cams, positive flank,negative direction of travel
(23) bis (30)	HOMSW	Left reference cam polarity, Stop at RefNock = Low	Various homing runs to cams
(31), (32)	-	Not defined	Reserved
(33)	-	Next left zero pulse	Zero impulse in negative direction of travel
(34)	-	Left reference cam polarity, Stop at RefNock = High	Zero impulse in positive direction of travel
(35)	-	Actual position = Reference position	The instantaneous position is the zero position

6.6 Homing run methods

The type of homing run is selected by the parameter 2261 (MPRO_402_HomingMethod) [Parameter list ⇨ Motion Profile ⇨ Homing].
Further information can be found in the YukonDrive user manual.

7. Examples of commissioning using manufacturer-specific telegrams

7.1 Position control using PPO 5

The following section describes how the drive can be simply and quickly commissionend in the position control mode.

Firstly the GSD file "LUST0A33.gsd" must be linked in during the PROFIBUS configuration phase and then the PPO type 5 selected. PPO type 5 consists of a PKW channel (8 byte) and 10 process data channels (20 byte). The process data area can be freely configured using this manufacturer-specific telegram. That means that the desired reference values and actual values can be mapped to a defined process data area. All mappable signals are listed in two signal tables, which can be accessed using the parameter editor under the folder Parameter list ð Fieldbus ð PROFIBUS-DP in the left tree structure of the operating tool. Within this folder directory, the signal list 1284 (COM_DP_Signal-List_Write) contains all possible process data signals that can be written, and the signal list 1285 (DP_SignalList_Read) contains all possible process data signals that can be read.
The user can assign the process data channels freely as required. The actual assignment can be found in the signal tables 915 and 916 [Parameter list ð Fieldbus ð PROFIBUSDP]. Signal table 915 (COM_DP_PZDSelectionWrite) contains all signals that can be sent by the control master to the drive. Signal table 916 (COM_DP_PZDSelectionRead) contains all signals that can be sent by the drive to the control master.

The following table shows an example of the process data area from the control master to the drive. For this purpose the sub-indexes in list 915 are assigned the stated parameter numbers.

Table 7.1 Example of assignment of the master-slave process data channel

Signal table 915 Sub-index	PZD area	Parameter number	Parameter name	Data type (value range)
0	1	967	Control word (COM_DP_Controlword)	U16 (0..65535)
1	2	1275	Target position (COM_DP_TargetPos)	I32 (-2147483648 .. 2147483647)
2	3	1275	Target position (COM_DP_TargetPos)	
3	4	1280	Control word 2 (COM_DP_Controlword2)	U16 (0..65535)
4	5	1277	Positioning velocity (COM_DP_PosVelocity)	I32 (-2147483648 .. 2147483647)
5	6	1277	Positioning velocity (COM_DP_PosVelocity)	
6	7	1278	Acceleration (COM_DP_Acc)	U16 (0..65535)
7	8	1279	Braking deceleration (COM_DP_Dec)	U16 (0..65535)
8	9	0	-	-
9	10	0	-	-

Each sub-index represents a 16-bit wide process data channel. For this reason for instance the target position that is sent as Int32 is mapped to sub-indices 1 and 2 in order to transmit a real 32 bits. The parameters available for selection and their data types are listed in chapter 6.
The configuration of the process data channels can be freely selected by the user in the sequence of the signal assignments. However the data type format must be complied with.

The following table shows an example of the process data area from the drive to the master. For this purpose the sub-indexes in list 916 are assigned the desired parameter numbers.

Table 7.2 Example of assignment of the slave-master process data channels

Signal table 915 Sub-index	PZD area	Parameter number	Parameter name	Data type (value range)
0	1	968	Status word (COM_DP_Statuswort)	U16 (0..65535)
1	2	1276	Actual position (COM_DP_Act-Pos1)	I32 (-2147483648 .. 2147483647)
2	3	1276	Actual position (COM_DP_Act-Pos1)	
3	4	1281	Status word 2 (COM_DP_Statusword2)	U16 (0..65535)
4	5	1271	Actual speed(COM_DP_ActSpeed)	I16 (-32768..32767)
5	6	-	-	-
6	7	-	-	-
7	8	-	-	-
8	9	-	-	-
9	10	-	-	-

The following parameters must then be set for position control mode:

1. **CON_CfgCon (300) : PCON(3)** **[Parameter list ⇨ Motor control]**
   This parameter allows the control mode to be changed. The setting PCON (PositionControl Mode) means that the drive is in position control mode.

2. **CON_REF_Mode (301) : RFG(0)** **[Parameter list ⇨ Motion Profile ⇨ Basic settings]**
   This parameter allows the mode of the position reference value to be input. The position reference value can be input directly or via a ramp generator. The setting RFG (Ramp Function Generator) means that the position reference value is input via a ramp generator.

3. **MPRO_CTRL_SEL (159) : PROFIBUS(7)** **[Parameter List ⇨ Motion Profile ⇨ Basic settings]**
   Über diesen Parameter wird der Steuerort eingestellt. In diesem Fall ist der Steuerort PROFIBUS auszuwählen.

4. **MPRO_CTRL_SEL (159) : PROFIBUS(7)** **[Parameter List ⇨ Motion Profile ⇨ Basic settings]**
   This parameter allows the control location to be set. In this instance the control location is selected as PROFIBUS.

7.2 Conversion of reference values and actual values using factor group parameters

In positioning applications the inputting of reference values and the return of actual values are generally performed using application-specific user units (mm, degrees, ...). The reference values and actual values of the drive are converted using what are called factor group parameters [Parameter list›Motion profile›Standardisation/units]. For these the user has the facility to differentiate between 3 different groups of parameters.
All 3 groups have the same task, which is to convert the user units to the fixed internal variables used by the servocontroller. The first factor group is based on the DSP402 standard. The parameters of this group are described in detail in the CANopen specification DSP402. The second factor group goes under the heading "Sercos". The parameters of this group refer to the Sercos specification "SERCOS interface" (Version 2.4 / February 2005). The parameters of this group are also described in detail in the respective specification. The third factor group is called "user spec" and is user-specific group. Since this factor group is not described in detail elsewhere, the use of parameters of this group is illustrated by means of an example.

The user can select the factor group using the parameter "MPRO_FG_Type".

Table 7.3 Parameters

Parameter number	Parameter name	Meaning
283	MPRO_FG_Type	Selection of the factor group (0) = STD/402 (1) = SERCOS (2) = USER

The parameters of the USER factor group are listed in the table below

Table 7.4 USER factor group

Parameter number	Parameter name	Meaning	Unit
270	MPRO_FG_PosNorm	Sensor resolution	[incr/rev]
271	MPRO_FG_Num	Numerator (position)	[rev]
272	MPRO_FG_Den	Denominator (position)	[POS]
274	MPRO_FG_SpeedFac	Speed factor	[rev/(min*SPEED)]
275	MPRO_FG_AccFac	Acceleration factor	[rev/(sec*sec*ACC)]
284	MPRO_FG_PosUnit	Position unit	String
285	MPRO_FG_PosExp	Position exponent	-
286	MPRO_FG_PosScaleFac	Position factor	-
287	MPRO_FG_SpeedUnit	Speed unit	String
288	MPRO_FG_SpeedExp	Speed exponent	-
289	MPRO_FG_SpeedScaleFac	Speed factor	-

Table 7.4 USER factor group, prosecution

Parameter number	Parameter name	Meaning	Unit
290	MPRO_FG_AccUnit	Acceleration unit	String
291	MPRO_FG_AccExp	Acceleration exponent	-
292	MPRO_FG_AccScaleFac	Acceleration factor	-
293	MPRO_FG_TorqueUnit	Torque unit	String
294	MPRO_FG_TorqueExp	Torque exponent	-
295	MPRO_FG_TorqueScaleFac	Torque factor	-

These define the internal resolution of the unit for

Position: rev

Speed: rev/min

Acceleration: rev/(sec*sec)

The units are automatically defined by the profiles themselves according to DSP402 or Sercos. The units can be input manually in User setting.

The parameters for unit and exponent refer to the display and have no effect on the standardisation of the variables themselves.

The following three formulae describe the conversion of user units into the units used internally in positioning mode. They refer to reference position, speed and acceleration.

$$\text{Reference position}_{\text{Intern}}\ [\text{rev}] = \text{COM\_DP\_REFPos}\ [\ \text{User unit}\ ] \bullet \frac{\text{MPRO\_FG\_Num [rev]}}{\text{MPRO\_FG\_Den [User unit]}}$$

The quotient of parameters MPRO_FG_Num and MPRO_FG_Den describes the ratio of user unit to motor revolutions. Furthermore is allows any gearing ratios or advance constants to be incorporated.

Positioning speed

The parameter MPRO_FG_SpeedFac offers the facility to change the number of decimal points for the positioning speed or the unit of the positioning speed.

$$\text{Positioning speed}_{\text{Intern}}\ \frac{[\text{rev}]}{[\text{min}]} = \text{COM\_DP\_REFSpeed}\ [\ \text{User unit}\ ] \bullet \text{MPRO\_FG\_SpeedFac}\ \frac{[\text{rev}]}{[\text{Min} \bullet \text{User unit}\ ]}$$

Positioning acceleration

The parameter MPRO_FG_AccFac offers the facility to change the number of decimal points for the positioning acceleration or the unit of the positioning acceleration.

$$\text{Positioning speed}_{\text{Intern}}\ \frac{[\text{rev}]}{[\text{sec}^2]} = \text{COM\_DP\_Acc}\ [\ \text{User unit}\ ] \bullet \text{MPRO\_FG\_AccFac}\ \frac{[\text{rev}]}{[\text{sec}^2 \bullet \text{User unit}\ ]}$$

7.3 Examples for setting the user factor group

The positioning instructions should be input in degrees, so that 360° corresponds to one revolution of the motor (65536 increments per revolution of the motor). The speed should be input in rpm and the acceleration in rpm/sec. This gives the following values:

P00270 Sensor resolution	= 655 36 [incr/rev]
P00271 Position numerator	= 1 [rev]
P00272 Position denominator	= 360 [POS] **
P00274 Speed factor	= 1 [rev/(min*SPEED)] ***
P00275 Acceleration factor	= 1/60 [rev /(sec*sec*ACC)] ****
P00284 Position unit (string)	= „Degree“
P00287 Speed unit (string)	= „1/min“
P00290 Acceleration unit (string)	= „1/(min*sec)“

** POS	= User unit for position
***SPEED	= User unit for speed
****ACC	= User unit for acceleration

7.4 Speed control using PPO 2

The following section describes how the drive can be simply and quickly commissioning in the speed control mode. Firstly the GSD file „LUST0A33.gsd“ must be linked in during the PROFIBUS configuration phase and then the PPO type 2 selected.

PPO type 2 consists of a PKW channel (8 byte) and six process data channels (12 byte). The process data area can be freely configured using this manufacturer-specific telegram. That means that the desired reference values and actual values can be mapped to a defined process data area. All mappable signals are listed in two signal tables, which can be accessed using the parameter editor under the folder Parameter list ð Fieldbus ð PROFIBUS-DP in the left tree structure of the operating tool. Within this folder directory, the signal list 1284 (COM_DP_SignalList_Write) contains all possible process data signals that can be written, and the signal list 1285 (DP_SignalList_Read) contains all possible process data signals that can be read.

The user can freely assign the process data area. The actual assignment can be found in the signal tables 915 and 916 (Parameter list Fieldbus PROFIBUSDP). Signal table 915 (COM_DP_PZDSelectionWrite) contains all signals that can be sent by the control master to the drive. Signal table 916 (COM_DP_PZDSelectionRead) contains all signals that can be sent by the drive to the control master.

The following table shows an example of the process data area from the control master to the drive. For this purpose the sub-indexes in list 915 are assigned the desired parameter numbers.

Table 7.5 Assignment of the master-slave process data channels

Signal table 915 Sub-index	PZD area	Parameter number	Parameter name	Data type (value range)
0	1	967	Control word (COM_DP_Controlword)	U16 (0..65535)
1	2	1270	Reference speed (COM_DP_RefSpeed)	I16 (-32768..32767)
2	3	1278	Acceleration (COM_DP_Acc)	U16 (0..65535)
3	4	1279	Braking deceleration (COM_DP_Dec)	U16 (0..65535)
4	5	-	-	-
5	6	-	-	-
6	7	-	-	-
7	8	-	-	-
8	9	-	-	-
9	10	-	-	-

Each sub-index represents a 16-bit wide process data channel. For this reason for instance an Int32 must be mapped to two sub-indices. The parameters available for selection and their data types are listed in table „Assignment of the master-slave process data channels".

The configuration of the process data areas can be freely selected by the user in the sequence of the signal assignments. The only requirement is that the data type format must be complied with. That means that a 32-bit variable also requires 2 process data channels.

The following table shows an example of the process data area from the drive to the master. For this purpose the sub-indexes in list 916 are assigned the desired parameter numbers.

Table 7.6 Assignment of the slave-master process data channels

Signal table 915 Sub-index	PZD area	Parameter number	Parameter name	Data type (value range)
0	1	968	Status word (COM_DP_Statuswort)	U16 (0..655 35)
1	2	1271	Actual speed (COM_DP_ActSpeed)	I16 (-32768..32767)
2	3	-	-	-
3	4	-	-	-
4	5	-	-	-
5	6	-	-	-
6	7	-	-	-
7	8	-	-	-
8	9	-	-	-
9	10	-	-	-

The following parameters must then be set for speed control mode:

1. **CON_CfgCon (300) : SCON(2) [Parameter list ⇨ control]**
   This parameter allows the operating mode to be changed. The setting SCON (Speed Control Mode means that the drive is in speed control mode.
2. **CON_REF_Mode (301) : RFG(0) [Parameter list ⇨ Motion Profile ⇨ Basic settings]**
   This parameter determines the mode of reference value input. The position reference value can be input directly or via a ramp generator. The setting RFG (Ramp Function Generator) means that the speed reference value is input via a ramp generator.
3. **MPRO_CTRL_SEL (159) : PROFIBUS(7) [Parameter list ⇨ Motion Profile ⇨ Basic settings]**
   This parameter allows the control location to be set. In this instance the control location is PROFIBUS.
4. **MPRO_REF_SEL (165) : PROFI(9) [Parameter list ⇨ Motion Profile ⇨ Basic settings]**
   This parameter allows configuration of the reference value selector. In this instance the reference values are taken from the PROFIBUS.

Once these settings have been performed, communication can be established between the master and drive.

7.4.1 Speed input

All factor group parameters are set to default values. The speed reference value can then be input scaled to the motor nominal speed. So a value of 16384 corresponds to a speed reference value of 100% of the motor nominal speed. By using the control word (section 3.2) the drive can then be operated in speed control mode.

7.5 Mappable parameters

All factor group parameters are set to default values. The speed reference value can then be input scaled to the motor nominal speed. So a value of 16384 corresponds to a speed reference value of 100% of the motor nominal speed.

Table 7.7 Mappable parameters

Parameter number	Parameter name	Write (1284)	Read (1285)	PZD Length
967	COM_DP_Controlword	X	X	1
968	COM_DP_Statusword	-	X	1
1280	COM_DP_Controlword2	X	X	1
1281	COM_DP_Statusword2	-	X	1
1270	COM_DP_RefSpeed	X	X	1
1271	COM_DP_ActSpeed	-	X	1
121	MPRO_Input_State	-	X	1
143	MPRO_Output_State	-	X	1
1274	COM_DP_RefPos	X	X	2
1276	COM_DP_ActPos1	-	X	2
207	MPRO_TAB_ActIdx	X	X	1
1275	COM_DP_TargetPos	X	X	2
1277	COM_DP_PosVelocity	X	X	2
1278	COM_DP_Acc	X	X	1
1279	COM_DP_Dec	X	X	1
1287	COM_DP_TMaxPos	X	X	1
1288	COM_DP_TMaxNeg	X	X	1
...	...	...	...	...

Further mappable parameters can be found in the signal tables 1284 (COM_DP_Signal-List_Write) and 1285 (DP_SignalList_Read) [Parameter List ⇨ Fieldbus ⇨ PROFIBUS-DP].

8. PROFIBUS parameters

The following table describes the PROFIBUS parameters that are available.

Table 8.1 PROFIBUS parameters

Parameter name	number	Value range	Default value	Can be changed	Data type	Meaning
COM_DP_CtrlConfig	1267	0 – 65535	0	Ja	U16	This parameter describes the function of each bit in the control word, parameter 967.
COM_DP_RefJogSpeed1	1268	- 4294967296 - 4294967295	0	Ja	I32	This parameter contains homing speed 1 in the jog mode
COM_DP_RefJogSpeed2	1269	- 4294967296 - 4294967295	0	Ja	I32	This parameter contains homing speed 2 in the jog mode
COM_DP_RefSpeed	1270	-32768 – 32767	0	Ja	I16	Speed reference value, written by the PROFIBUS
COM_DP_ActSpeed	1271	-32768 – 32767	0	Nein	I16	Actual speed
COM_DP_RefTorque	1272	-32768 – 32767	0	Ja	I16	Torque reference value, written by the PROFIBUS
COM_DP_ActTorque	1273	-32768 – 32767	0	Nein	I16	Actual torque
COM_DP_RefPos	1274	-2147483648 – 2147483647	0	Ja	I32	Position reference value (ramp mode), written by the PROFIBUS
COM_DP_TargetPos	1275	-2147483648 – 2147483647	0	Ja	I32	Position reference value (direct mode), written by the PROFIBUS
COM_DP_ActPos1	1276	-2147483648 – 2147483647	0	Nein	I32	Actual position from 1st position sensor
COM_DP_PosVelocity	1277	-2147483648 – 2147483647	0	Ja	I32	Speed reference value (ramp mode), written by the PROFIBUS
COM_DP_Acc	1278	0 – 0xFFFF	100	Ja	U16	Acceleration reference value (ramp mode), written by the PROFIBUS
COM_DP_Dec	1279	0 – 0xFFFF	100	Ja	U16	Deceleration reference value (ramp mode), written by the PROFIBUS
COM_DP_Controlword2	1280	0 – 0xFFFF	0	Ja	U16	2nd Control value, not used at first
COM_DP_Statusword2	1281	0 – 0xFFFF	0	Nein	U16	2nd status value, not used at first
COM_DP_Bus_Timeout	1283	0 – 4294967295	5000	Ja	U32	Bus timeout
COM_DP_SignalList_ write	1284	0 – 65535	0	Nein	U16	List of parameters that can be used as process data reference values

Table 8.1 PROFIBUS parameters, prosecution

Parameter name	number	Value range	Default value	Can be changed	Data type	Meaning
COM_DP_TMaxScale	1286	0 – 2000	1000	Ja	U16	Online torque scaling
COM_DP_SignalList_ Read	1285	0 – 65535	0	Nein	U16	List of parameters that can be used as process data reference values
COM_DP_TMaxPos	1287	0 – 2000	1000	Ja	U16	Positive online torque scaling
COM_DP_TMaxNeg	1288	0 – 2000	1000	Ja	U16	Negative online torque scaling
COM_DP_PZDSelection-Write	915	0 – 65535	967	Ja	U16	This parameter allows incoming process data to be linked to specific device parameters. The parameters that can be entered are listed in parameter 1284. The sub-index 0 contains the first process data value PZD1 and so on.
COM_DP_PZDSelection-Read	916	0 – 65535	968	Ja	U16	This parameter allows outgoing process data to be linked to specific device parameters. The parameters that can be entered are listed in parameter 1285. The sub-index 0 contains the first process data value PZD1 and so on.
COM_DP_Address	918	0 – 126	126	Ja	U16	Station address of the inverter
COM_DP_TelegramSe-lection	922	0 – 65535	0	Ja	U16	
COM_DP_SignalList	923	0 – 65535	0	Nein	U16	This parameter lists all “mappable” parameters and signals for param-eters 915 and 916.
COM_DP_Warning	953	0 – 0xFFFF	0	Nein	U16	This parameter forwards warning messages from the PROFIBUS. These include bus timeout and PLC stop mode.
COM_DP_Baudrate	963	9.6 – 45.45 kbits/s	9.6 kbit/s	Nein	U16	Current Baud rate for bus communication
COM_DP_DeviceId	964	0 – 65535	0	Nein	U16	This parameter is for device identification
COM_DP_ProfileNo	965	0 – 65535	0	Nein	U16	Profile number, not supported in the first step
COM_DP_Controlword	967	0 – 0xFFFF	0	Ja	U16	Control word for the internal status machine

Table 8.1 PROFIBUS parameters, prosecution

Parameter name	Number	Value range	Default Value	can be changed	Data type	Meaning
COM_DP_Statusword	968	0 – 0xFFFF	0	Nein	U16	Status word for the internal status machine
COM_DP_DataStore	971	0 – 255	0	Ja	U16	This parameter permits storage of data in the non-volatile memory
COM_DP_DefinedParameter	980	0 – 65535	0	Nein	U16	This parameter describes the defined parameters in the drive controller.
COM_DP_ModifiedParameter	990	0 – 65535	0	Nein	U16	This parameter describes all the parameters in the drive controller that are not set to the "default" values.

Appendix Glossary

AK	Request identification
Application dat set	Factory pre-defined data set for solution of typical applications
Diagnostic data	The master reads the diagnostic data from the slave and thus permits a central response to slave malfunctions.
DP	Distributed I/O
Master	The supervisory controller which provides communications.
MW	Flag word
Parameter data	The PKW parameter channel is used to transmit parameters cyclically to and from the drive device.
PKW	Parameter identification value
PNU	Parameter number
ProfiDrive Mode	Configuration of the process data channel, compatible with the ProfiDrive profile. In contrast to EasyDrive mode the system statuses are changed by defined series of control sequences. The system status machine defined in the PROFIBUS standard specifies the individual system status transitions.
PZD	Process data: The process data channel contains the functions “Load control and status”, “Input reference values” and “Display actual values”.
Slave	A slave is a bus participant on the PROFIBUS-DP, which in contrast to the master responds exclusively to the requests directed to it.
SPM	Spontaneous message
Status machine	This describes the transitions between the various systems statuses. A status transitions is triggered by a defined event such as a control sequence or the setting of an input.

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Änderungen vorbehalten.
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